

AMENDMENTS TO THE CLAIMS

1. (Currently amended) A haptic feedback apparatus comprising:

an elongate intervention device carrying at least one force sensor and operable to be inserted into a human or animal subject together with the at least one force sensor, the at least one force sensor arranged to sense a remote force in the human or animal subject acting on the intervention device;

a force applicator arranged to apply a force to ~~an~~ the elongate intervention device, ~~the intervention device carrying at least one force sensor arranged to sense a remote force acting on the intervention device;~~

a controller arranged to control the force applied to the intervention device by the force applicator, the controller being connected to the at least one force sensor and configured ~~arranged~~ to calculate the applied force based on the remote force, the applied force being an amplification of the remote force,

wherein the force applicator comprises a resilient member arranged to apply the said force to the intervention device, and

wherein the apparatus further comprises a sensor arranged to detect frictional force between the resilient member and the intervention device.

2. (Currently amended) The haptic feedback apparatus ~~according to~~ of claim 1, wherein the detected frictional force is used to control an amount of applied force.

3. (Currently amended) The haptic feedback apparatus ~~according to~~ of claim 1, further comprising a tracking device for tracking rotational movement of the intervention device.

4. (Currently amended) The haptic feedback apparatus ~~according to~~ of claim 1, further comprising a tracking device for tracking linear movement of the intervention device.

5. (Currently amended) The haptic feedback apparatus ~~according to~~ of claim 1, further comprising a comparator for comparing the remote force with a reference force.

6. (Currently amended) The haptic feedback apparatus ~~according to~~ of claim 1, wherein the intervention device and the at least one force sensor are suitable for insertion into a simulated human model.

7. (Currently amended) The haptic feedback apparatus ~~according to~~ of claim 6, wherein the remote force is generated using computer simulation.

8. (Cancelled).

9. (Currently amended) The haptic feedback apparatus ~~according to~~ of claim ~~[[8]]~~ 1, wherein the at least one force sensor is disposed near or at a tip of the intervention device.

10. (Currently amended) The haptic feedback apparatus ~~according to~~ of claim 7, further comprising a plurality of force sensors disposed along a length of the intervention device and the controller is connected to each of the plurality of force sensors.

Claims 11-36. (Cancelled)

37. (Currently amended) The haptic feedback apparatus ~~according to~~ of claim 9, wherein the at least one force sensor is embedded in the intervention device.

38. (Currently amended) The haptic feedback apparatus ~~according to~~ of claim 10, wherein the plurality of force sensors are arranged to detect a shape of the intervention device.

39. (Currently amended) The haptic feedback apparatus ~~according to~~ of claim 10, wherein the plurality of force sensors are embedded in the intervention device.

40. (New) A haptic feedback apparatus comprising:

an elongate intervention device carrying at least one force sensor and operable to be inserted into a simulated human or animal model together with the at least one force sensor, the at least one force sensor arranged to sense a remote force in the simulated human or animal model acting on the intervention device;

a force applicator arranged to apply a force to the elongate intervention device;

a controller arranged to control the force applied to the intervention device by the force applicator, the controller being connected to the at least one force sensor and configured to calculate the applied force based on the remote force, the applied force being an amplification of the remote force,

wherein the force applicator comprises a resilient member arranged to apply the said force to the intervention device, and

wherein the apparatus further comprises a sensor arranged to detect frictional force between the resilient member and the intervention device.